AMENDMENTS TO THE SPECIFICATION

IN THE SPECIFICATION:

Page 4

Please amend the Specification on page 4 beginning at line 4 as follows:

~~[*The autopilot of the present invention also has an interrupt controller for independently changing the turning direction, the turning radius and the turning center position, all of which are stored in the memory.*]~~

The autopilot of the present invention also has an interrupt controller for independently changing the turning direction, the turning radius and the turning center position, all of which are stored in the memory.

Page 11

Please amend the Specification on page 11 beginning at line 11 as follows:

A procedure for the adjustment will be described as follows.

(S0) An initial evaluated value is calculated in accordance with expression (1):

~~eval = R_err^2 + 0.1*dv_g^2 (1)~~ eval = $R\_err^2 + 0.1*dv\_g^2$ (1)

where R_err is the radius error, dv_g is the deviation angle, 0.1 preceding dv_g is a coefficient obtained by experiments (the coefficient is not limited to this value).

Page 12

Please amend the Specification on page 12 beginning at line 8 as follows:

(ii) When eval < eval_last ~~(Yes in S5 of FIG. 6 [*FIG.7*]), (~~Yes in S5 of FIG.7), it means that the evaluation becomes better, i.e., the process of (S3) has a satisfactory result. Therefore, Δkp is further added. The resultant kp is larger than by 2×Δkp than kp before the addition in (S3).